as set forth below to place the application in condition for allowance.

IN THE CLAIMS:

Please cancel claims 12-18 without prejudice.

Please amend claims 1 and 19 as follows:

1. (Currently Amended) A method of determining a relative position and orientation between a base camera and a non-base camera, comprising:

measuring a path of ~~an~~ a moving object with the base camera in a base coordinate frame;

measuring the object path with the non-base camera in a non-base coordinate frame;

calculating transformation parameters based on the object path;

applying the transformation parameters to the object path measured by the non-base camera such that the object path measured by the non-base camera is expressed in the base coordinate frame.

2. (Previously Presented) The method of claim 1, wherein the object path is a path of a person moving around a scene.

3. (Original) The method of claim 1, wherein calculating transformation parameters comprises performing matching of data measured by the base and non-base cameras.

4. (Original) The method of claim 3, wherein data matching is used to solve a set of transformation equations.

5. (Original) The method of claim 4, wherein data matching comprises selecting a time value and matching points of the object path as measured by the base camera at the time value with points of the object path as measured by the non-base

camera at the time value.

6.   (Original) The method of claim 5, wherein interpolation is used to generate a data point at the time value if no data point was measured at the time value.

7.   (Original) The method of claim 3, further comprising using an error minimization technique to determine transformation parameters with the least amount of error.

8.   (Original) The method of claim 7, wherein the error minimization technique is a least squares solution.

9.   (Original) The method of claim 7, wherein the error minimization technique is a least median of squares solution.

10.   (Original) The method of claim 3, further comprising applying a time offset to data from at least one of the base and non-base cameras to correct for unsynchronized data between the base and non-base cameras.

11.   (Original) The method of claim 10, wherein a set of time offset value and corresponding transformation parameters are calculated and an error minimization technique is used to determine the time offset value with the least amount of error.

12.   (Canceled)

13.   (Canceled)

14.   (Canceled)

15.   (Canceled)

16.   (Canceled)

17.   (Canceled)

18.   (Canceled)

19.   (Currently Amended) A method of calibrating a first and a second range camera, comprising:

measuring a path of ~~an~~ a moving object with the first range camera to generate a first observed object path;

measuring the object path with the second range camera to generate a second observed object path; and

calculating a transformation parameter that causes the first observed object path to approximately overlap with the second observed object path so as to determine a relative pose between the first and second range cameras.

20.   (Original) The method of claim 19, wherein the transformation parameter is calculated using a time offset value.

21.   (Canceled)

22.   (Canceled)

23.   (Canceled)

24.   (Canceled)

25.   (Canceled)